

# Refine Search

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Your wildcard search against 10000 terms has yielded the results below.

***Your result set for the last L# is incomplete.***

The probable cause is use of unlimited truncation. Revise your search strategy to use limited truncation.

## Search Results -

Terms	Documents
L39 and (compar\$ same (colinear\$ or regressi\$) same error\$)	0

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**Database:**

 US Pre-Grant Publication Full-Text Database  
 US Patents Full-Text Database  
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 JPO Abstracts Database  
 Derwent World Patents Index  
 IBM Technical Disclosure Bulletins

**Search:**

10/605768	<input type="button" value="Refine Search"/>
<input style="margin-right: 10px;" type="button" value="Recall Text"/> <input type="button" value="Clear"/> <input type="button" value="Interrupt"/>	

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## Search History

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Set  
Name Query  
 side by  
 side

Hit Set  
Count Name  
 result  
 set

*DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD;*  
*THES=ASSIGNEE; PLUR=YES; OP=OR*

L39 and (compar\$ same (colinear\$ or regressi\$) same

<u>L52</u>	error\$)	0	<u>L52</u>
<u>L51</u>	L39 and (compar\$ same (colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L51</u>
<u>L50</u>	L39 and (compar\$ same confiden\$ same (threshold\$ with error\$))	0	<u>L50</u>
<u>L49</u>	L39 and (compar\$ same (confiden\$) same (threshold\$ with error\$))	0	<u>L49</u>
<u>L48</u>	L39 and gps\$ and vehicle and (compar\$ same (confiden\$) same (threshold\$ with error\$))	0	<u>L48</u>
<u>L47</u>	L39 and gps\$ and vehicle and (compar\$ same (colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L47</u>
<u>L46</u>	L41 and gps\$ and vehicle and (compar\$ same (colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L46</u>
<u>L45</u>	L44 and gps\$ and vehicle and (compar\$ same (colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L45</u>
<i>DB=USPT; THES=ASSIGNEE; PLUR=YES; OP=OR</i>			
<u>L44</u>	L43 and (compar\$ same (driver\$ near4 input\$))	10	<u>L44</u>
<i>DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD;</i>			
<i>THES=ASSIGNEE; PLUR=YES; OP=OR</i>			
<u>L43</u>	L42 and inputs	26	<u>L43</u>
<u>L42</u>	L41 and (driver\$ near4 input\$)	26	<u>L42</u>
<u>L41</u>	L40 and ((automobile or vehicle or car\$ or driv\$) same input\$)	97	<u>L41</u>
<u>L40</u>	L39 and ((701/201   701/202   701/208   701/209   701/210   701/211   701/213).ccls.)	150	<u>L40</u>
<u>L39</u>	L37 or L38	530	<u>L39</u>
<u>L38</u>	((compar\$ with (path\$ or way\$ or route\$)) same gps\$) and @pd<=20031024	306	<u>L38</u>
<u>L37</u>	((compar\$ with (path\$ or way\$ or route\$)) same gps\$) and @ad<=20031024	521	<u>L37</u>
<i>DB=PGPB,USPT,USOC; THES=ASSIGNEE; PLUR=YES;</i>			
<i>OP=OR</i>			

<u>L36</u>	L35 and @ad<=20031024 L34 and ((compar\$ with (path\$ or way or route)) with predict\$ or forecast\$) and ((calculat\$ or desire\$ or plan\$) with (path\$ or way or route))	26	<u>L36</u>
<u>L35</u>	(701/202  701/208  701/209  701/210  701/213).ccls. <i>DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD;</i> <i>THES=ASSIGNEE; PLUR=YES; OP=OR</i>	41	<u>L35</u>
<u>L34</u>	(701/202  701/208  701/209  701/210  701/213).ccls. <i>DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD;</i> <i>THES=ASSIGNEE; PLUR=YES; OP=OR</i>	5214	<u>L34</u>
<u>L33</u>	L32 and ((calculat\$ or desire\$ or plan\$) with (path\$ or way or route))	21	<u>L33</u>
<u>L32</u>	L30 and ((compar\$ with (path\$ or way or route)) with predict\$ or forecast\$))	34	<u>L32</u>
<u>L31</u>	L30 and (compar\$ with (predict\$ or forecast\$))	36	<u>L31</u>
<u>L30</u>	L16 and ((701/201  701/202  701/208  701/209  701/210  701/211  701/213).ccls.)	44	<u>L30</u>
<u>L29</u>	L28 and ((701/201  701/202  701/208  701/209  701/210  701/211  701/213).ccls.)	1	<u>L29</u>
<u>L28</u>	L24 or L25	45	<u>L28</u>
<u>L27</u>	L26	9	<u>L27</u>
<u>L26</u>	L25	9	<u>L26</u>
<u>L25</u>	(linear\$ with regression\$) and (pitch\$ and yaw\$ and speed\$ or velocit\$) and L11	9	<u>L25</u>
<u>L24</u>	(linear\$ with regression\$) and (pitch\$ and yaw\$ and speed\$ or velocit\$) and gps\$	45	<u>L24</u>
<u>L23</u>	(linear\$ with regression\$) and (pitch\$ and yaw\$ and speed\$ or velocit\$) and L16	1	<u>L23</u>
<u>L22</u>	(linear\$ adj regression\$) and (pitch\$ and yaw\$ and speed\$ or velocit\$) and L16	1	<u>L22</u>
<u>L21</u>	(linear\$ adj regression\$ adj model\$) and (pitch\$ and yaw\$ and (speed\$ or velocit\$)) and L16	1	<u>L21</u>
<u>L20</u>	L19 and (pitch\$ or yaw\$ or (speed\$ or velocit\$))	2	<u>L20</u>
<u>L19</u>	L16 and (linear\$ adj regression\$ adj model\$)	2	<u>L19</u>
<u>L18</u>	L17 and ((speed\$ or velocit\$) with (vehicle or car\$ or automobil\$))	7	<u>L18</u>
<u>L17</u>	L16 and ((confide\$ or trust\$ or reliab\$) near2	16	<u>L17</u>

(degree\$ or level\$ or scal\$))

<u>L16</u>	L14 or L15	189	<u>L16</u>
<u>L15</u>	L13 and @pd<=20031024	122	<u>L15</u>
<u>L14</u>	L13 and @ad<=20031024	189	<u>L14</u>
<u>L13</u>	gps\$ and ((compar\$ with (path\$ or way or route)) same (predict\$ or forecast\$))	287	<u>L13</u>
<u>L12</u>	L10 and @pd<=20031024	5820	<u>L12</u>
<u>L11</u>	L10 and @ad<=20031024	9464	<u>L11</u>
<u>L10</u>	gps\$ and ((compar\$ with (path\$ or way or route)) sme (predict\$ or forecast\$))	15325	<u>L10</u>

*DB=EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES;  
OP=OR*

<u>L9</u>	gps\$ and vehicle and ((compar\$ with confiden\$) same error\$)	0	<u>L9</u>
<u>L8</u>	gps\$ and vehicle and ((compar\$ with confiden\$) same (threshold\$ with error\$))	0	<u>L8</u>
<u>L7</u>	gps\$ and vehicle and ((colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L7</u>
<u>L6</u>	gps\$ and vehicle and (compar\$ same (colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L6</u>

*DB=PGPB; THES=ASSIGNEE; PLUR=YES; OP=OR*

<u>L5</u>	L1 and (chaos\$ same compar\$)	1	<u>L5</u>
<u>L4</u>	L1 and threshold\$.clm.	1	<u>L4</u>
<u>L3</u>	L1 and (error\$ same threshold\$)	1	<u>L3</u>
<u>L2</u>	L1 and (colinear\$ same confiden\$)	1	<u>L2</u>
<u>L1</u>	20050090938	1	<u>L1</u>

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to:

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- Combine search queries using AND, OR, or NOT
- Delete a search
- Run a search

**Search Query Display**

10/605768

**Recent Search Queries**

- |           |   |
|-----------|---|
| <u>#1</u> | (compar* <paragraph> ((colinear* <or> regression*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata |
| <u>#2</u> | (compar* <and> ((colinear* <or> regression*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata       |
| <u>#3</u> | (compar* <and> ((colinear* <or> regression*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata       |
| <u>#4</u> | (compar* <and> ((colinear* <or> regression*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata       |
| <u>#5</u> | (compar* <and> ((colinear* <or> regressi*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata         |
| <u>#6</u> | (compar* <and> ((co-linear* <or> regressi*) <sentence> confiden*) <paragraph> (thres-hold* <sentence> error*)) <in> pdfdata       |
| <u>#7</u> | (compar* <and> ((co-linear* <or> regressi*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata        |
| <u>#8</u> | (compar* <and> ((co-linear* <or> regressi*) <sentence> confiden*) <paragraph> (threshold* <sentence> error*)) <in> pdfdata        |

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**SEARCH RESULTS**

Results for "(compar\* <and> ((colinear\* <or> regression\*) <sentence> confiden\*) <paragraph> &g..."  
Your search matched 1 of 1632036 documents.  
A maximum of 100 results are displayed, 25 to a page, sorted by Relevance in Descending order.

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(compar\* <and> ((colinear\* <or> regression\*) <sentence> confiden\*) <paragraph> (th)

Check to search only within this results set

Display Format:  Citation  Citation & Abstract

[Select All](#) [Deselect All](#)

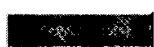
1. Optimization of voiced/Unvoiced decisions in nonstationary noise enviro  
Kobatake, H.;  
Acoustics, Speech, and Signal Processing [see also IEEE Transactions on Sig  
IEEE Transactions on  
Volume 35, Issue 1, Jan 1987 Page(s):9 - 18  
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## Optimization of voiced/Unvoiced decisions in nonstationary environments

**Kobatake, H.**

Tokyo University of Agriculture and Technology, Tokyo, Japan

This paper appears in: [Acoustics, Speech, and Signal Processing \[see also IEEE Transactions on Processing\], IEEE Transactions on](#)

Publication Date: Jan 1987

Volume: 35 , Issue: 1

On page(s): 9 - 18

ISSN: 0096-3518

Posted online: 2003-01-29 10:33:02.0

**Abstract**

This paper describes a way of optimizing the autocorrelation method of voiced/unvoiced which is heavily degraded by nonstationary ambient noise. Usually a constant threshold is used to decide whether the correlation peak value is compared for voiced/ unvoiced decision. The optimal threshold depends on the function of noise characteristics and the signal-to-noise ratio. This paper presents a method of estimating the threshold based on the probability density function of correlation peak values from noisy speech and also of estimating the error rate of the voiced/unvoiced decision. The performance of the proposed method has been tested under various noise characteristics and signal-to-noise ratios. The estimated threshold is very close to the true optimal threshold in almost all cases. The method also retains the optimality under slowly time-varying noise conditions, even if no a priori information is available about noise characteristics or noise level.

**Index Terms****Inspec****Controlled Indexing**

Not Available

**Non-controlled Indexing**

Not Available

**Author Keywords**

Not Available

**References**

No references available on IEEE Xplore.

**Citing Documents**

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# Refine Search

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## Search Results -

Terms	Documents
gps\$ and vehicle and ((compar\$ with confiden\$) same error\$)	0

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**Database:**

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**Search:**

10/605, 768		<input type="button" value="Refine Search"/>
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## Search History

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[Create Case](#)

<u>Set</u>	<u>Name</u>	<u>Query</u>	<u>Hit Count</u>	<u>Set Name</u>
side by side				result set

*DB=EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES;  
OP=OR*

- |           |   |          |           |
|-----------|---|----------|-----------|
| <u>L9</u> | <u>gps\$ and vehicle and ((compar\$ with confiden\$) same error\$)</u>                    | <u>0</u> | <u>L9</u> |
| <u>L8</u> | <u>gps\$ and vehicle and ((compar\$ with confiden\$) same (threshold\$ with error\$))</u> | <u>0</u> | <u>L8</u> |
|           | <u>gps\$ and vehicle and ((colinear\$ or regressi\$) same</u>                             |          |           |

<u>L7</u>	(threshold\$ with error\$))	0	<u>L7</u>
<u>L6</u>	gps\$ and vehicle and (compar\$ same (colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L6</u>
<i>DB=PGPB; THES=ASSIGNEE; PLUR=YES; OP=OR</i>			
<u>L5</u>	L1 and (chaos\$ same compar\$)	1	<u>L5</u>
<u>L4</u>	L1 and threshold\$.clm.	1	<u>L4</u>
<u>L3</u>	L1 and (error\$ same threshold\$)	1	<u>L3</u>
<u>L2</u>	L1 and (colinear\$ same confiden\$)	1	<u>L2</u>
<u>L1</u>	20050090938	1	<u>L1</u>

END OF SEARCH HISTORY

# Refine Search

---

Your wildcard search against 10000 terms has yielded the results below.

***Your result set for the last L# is incomplete.***

The probable cause is use of unlimited truncation. Revise your search strategy to use limited truncation.

## Search Results -

Terms	Documents
L58 and (compar\$ same (predict\$ with path\$) same (desir\$ with path\$))	1

**Database:**

US Pre-Grant Publication Full-Text Database  
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 Derwent World Patents Index  
 IBM Technical Disclosure Bulletins

**Search:**

10/605,768	<input style="border: 1px solid black; padding: 2px; margin-right: 10px;" type="button" value="Recall Text"/> <input style="border: 1px solid black; padding: 2px;" type="button" value="Clear"/>	<input style="border: 1px solid black; padding: 2px;" type="button" value="Refine Search"/> <input style="border: 1px solid black; padding: 2px;" type="button" value="Interrupt"/>
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## Search History

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**DATE: Saturday, August 18, 2007**    [Purge Queries](#)    [Printable Copy](#)  
[Create Case](#)

Set  
Name Query  
 side by  
 side

Hit Set  
Count Name  
 result  
 set

*DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD;*  
*THES=ASSIGNEE; PLUR=YES; OP=OR*

<u>L59</u>	L58 and (compar\$ same (predict\$ with path\$) same (desir\$ with path\$))	1	<u>L59</u>
<u>L58</u>	154 or 155 or 156 or 157  <i>DB=USPT; THES=ASSIGNEE; PLUR=YES; OP=OR</i> (4897642   5043736   5146231   4672382   5173709	50	<u>L58</u>
<u>L57</u>	4881080   5089816   2861264   4599620   4949089   4954833   4903212   4741245)![PN]	13	<u>L57</u>
<u>L56</u>	("5266958")[PN]  <i>DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD;</i> <i>THES=ASSIGNEE; PLUR=YES; OP=OR</i>	1	<u>L56</u>
<u>L55</u>	153  <i>DB=USPT; THES=ASSIGNEE; PLUR=YES; OP=OR</i>	1	<u>L55</u>
<u>L54</u>	("5266958")[URPN]  <i>DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD;</i> <i>THES=ASSIGNEE; PLUR=YES; OP=OR</i>	36	<u>L54</u>
<u>L53</u>	113 and (compar\$ same (predict\$ with path\$) same (desir\$ with path\$))	1	<u>L53</u>
<u>L52</u>	L39 and (compar\$ same (colinear\$ or regressi\$) same error\$)	0	<u>L52</u>
<u>L51</u>	L39 and (compar\$ same (colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L51</u>
<u>L50</u>	L39 and (compar\$ same confiden\$ same (threshold\$ with error\$))	0	<u>L50</u>
<u>L49</u>	L39 and (compar\$ same (confiden\$) same (threshold\$ with error\$))	0	<u>L49</u>
<u>L48</u>	L39 and gps\$ and vehicle and (compar\$ same (confiden\$) same (threshold\$ with error\$))	0	<u>L48</u>
<u>L47</u>	L39 and gps\$ and vehicle and (compar\$ same (colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L47</u>
<u>L46</u>	L41 and gps\$ and vehicle and (compar\$ same (colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L46</u>
<u>L45</u>	L44 and gps\$ and vehicle and (compar\$ same (colinear\$ or regressi\$) same (threshold\$ with	0	<u>L45</u>

error\$))

*DB=USPT; THES=ASSIGNEE; PLUR=YES; OP=OR*

L44 L43 and (compar\$ same (driver\$ near4 input\$)) 10 L44

*DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD;*  
*THES=ASSIGNEE; PLUR=YES; OP=OR*

L43 L42 and inputs 26 L43

L42 L41 and (driver\$ near4 input\$) 26 L42

L41 L40 and ((automobile or vehicle or car\$ or driv\$) same input\$) 97 L41

L40 L39 and ((701/201 | 701/202 | 701/208 | 701/209 | 701/210 | 701/211 | 701/213).ccls.) 150 L40

L39 L37 or L38 530 L39

L38 ((compar\$ with (path\$ or way\$ or route\$)) same gps\$) and @pd<=20031024 306 L38

L37 ((compar\$ with (path\$ or way\$ or route\$)) same gps\$) and @ad<=20031024 521 L37

*DB=PGPB,USPT,USOC; THES=ASSIGNEE; PLUR=YES;*  
*OP=OR*

L36 L35 and @ad<=20031024 26 L36

L35 L34 and ((compar\$ with (path\$ or way or route)) with (predict\$ or forecast\$)) and ((calculat\$ or desire\$ or plan\$) with (path\$ or way or route)) 41 L35

L34 (701/202 | 701/208 | 701/209 | 701/210 | 701/213).ccls. 5214 L34

*DB=PGPB,USPT,USOC,EPAB,JPAB,DWPI,TDBD;*  
*THES=ASSIGNEE; PLUR=YES; OP=OR*

L33 L32 and ((calculat\$ or desire\$ or plan\$) with (path\$ or way or route)) 21 L33

L32 L30 and ((compar\$ with (path\$ or way or route)) with (predict\$ or forecast\$)) 34 L32

L31 L30 and (compar\$ with (predict\$ or forecast\$)) 36 L31

L30 L16 and ((701/201 | 701/202 | 701/208 | 701/209 | 701/210 | 701/211 | 701/213).ccls.) 44 L30

L29 L28 and ((701/201 | 701/202 | 701/208 | 701/209 | 701/210 | 701/211 | 701/213).ccls.) 1 L29

<u>L28</u>	L24 or L25	45	<u>L28</u>
<u>L27</u>	L26	9	<u>L27</u>
<u>L26</u>	L25	9	<u>L26</u>
<u>L25</u>	(linear\$ with regression\$) and (pitch\$ and yaw\$ and (speed\$ or velocit\$)) and L11	9	<u>L25</u>
<u>L24</u>	(linear\$ with regression\$) and (pitch\$ and yaw\$ and (speed\$ or velocit\$)) and gps\$	45	<u>L24</u>
<u>L23</u>	(linear\$ with regression\$) and (pitch\$ and yaw\$ and (speed\$ or velocit\$)) and L16	1	<u>L23</u>
<u>L22</u>	(linear\$ adj regression\$ adj model\$) and (pitch\$ and yaw\$ and (speed\$ or velocit\$)) and L16	1	<u>L22</u>
<u>L21</u>	(linear\$ adj regression\$ adj model\$) and (pitch\$ and yaw\$ and (speed\$ or velocit\$)) and L16	1	<u>L21</u>
<u>L20</u>	L19 and (pitch\$ or yaw\$ or (speed\$ or velocit\$))	2	<u>L20</u>
<u>L19</u>	L16 and (linear\$ adj regression\$ adj model\$)	2	<u>L19</u>
<u>L18</u>	L17 and ((speed\$ or velocit\$) with (vehicle or car\$ or automobil\$))	7	<u>L18</u>
<u>L17</u>	L16 and ((confide\$ or trust\$ or reliab\$) near2 (degree\$ or level\$ or scal\$))	16	<u>L17</u>
<u>L16</u>	L14 or L15	189	<u>L16</u>
<u>L15</u>	L13 and @pd<=20031024	122	<u>L15</u>
<u>L14</u>	L13 and @ad<=20031024	189	<u>L14</u>
<u>L13</u>	gps\$ and ((compar\$ with (path\$ or way or route)) same (predict\$ or forecast\$))	287	<u>L13</u>
<u>L12</u>	L10 and @pd<=20031024	5820	<u>L12</u>
<u>L11</u>	L10 and @ad<=20031024	9464	<u>L11</u>
<u>L10</u>	gps\$ and ((compar\$ with (path\$ or way or route)) sme (predict\$ or forecast\$))	15325	<u>L10</u>

DB=EPAB,JPAB,DWPI,TDBD; THES=ASSIGNEE; PLUR=YES;  
OP=OR

<u>L9</u>	gps\$ and vehicle and ((compar\$ with confiden\$) same error\$)	0	<u>L9</u>
<u>L8</u>	gps\$ and vehicle and ((compar\$ with confiden\$) same (threshold\$ with error\$))	0	<u>L8</u>

<u>L7</u>	gps\$ and vehicle and ((colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L7</u>
<u>L6</u>	gps\$ and vehicle and (compar\$ same (colinear\$ or regressi\$) same (threshold\$ with error\$))	0	<u>L6</u>
<i>DB=PGPB; THES=ASSIGNEE; PLUR=YES; OP=OR</i>			
<u>L5</u>	L1 and (chaos\$ same compar\$)	1	<u>L5</u>
<u>L4</u>	L1 and threshold\$.clm.	1	<u>L4</u>
<u>L3</u>	L1 and (error\$ same threshold\$)	1	<u>L3</u>
<u>L2</u>	L1 and (colinear\$ same confiden\$)	1	<u>L2</u>
<u>L1</u>	20050090938	1	<u>L1</u>

END OF SEARCH HISTORY